

FIG. 2A

| MOTION (TRANSLATION) INFORMATION | Symbol | OPERATION ON RAW DATA | Explanations |
|--|--------|--------------------------|------------------------------|
| Time span | T | range | |
| Region | R | area, \cap | |
| Begin point | B | \subset | contained in |
| End point | E | \subset | contained in |
| Speed range | S | \cap, \subset, \supset | |
| Direction | V | $=_0$ | |
| Accel range | A | \cap, \subset, \supset | |
| Shape | H | $=$ | |
| Path | P | $\Sigma, =_1, =_0$ | union, time shifted, overlap |

FIG. 2B

| Motion patterns examples | Query based on operators (α, β are user input/parameters) |
|--|---|
| <ul style="list-style-type: none"> Object stopping Object moving fast Active region Source region Beaten path Road Convoy Ran a traffic light Illegal parking | <p> $\{J: J.A \cap [-\infty, 0) \text{ and } 0 \in J.S\}$ $\{J: J.S \in [\alpha, \infty)\}$ $R = \cap J_i.R$, where $\{ J_i \} > \alpha$ and $R.area < \beta$ $R = \cap J_i.B$, where $\{ J_i \} > \alpha$ and $R.area < \beta$ $P = \Sigma J_i.P$, where $\forall J_i, \{ J_k: J_k =_0 J_i \} > \alpha$ beaten path with $\alpha=1$ $\Gamma = \{J_i: \forall J_i \in \Gamma \exists J_k \in \Gamma, \text{ where } J_i =_1 J_k \text{ and } \Gamma \geq \alpha$ deviation from traffic direction object stopped while object in front moves </p> |

FIG. 3

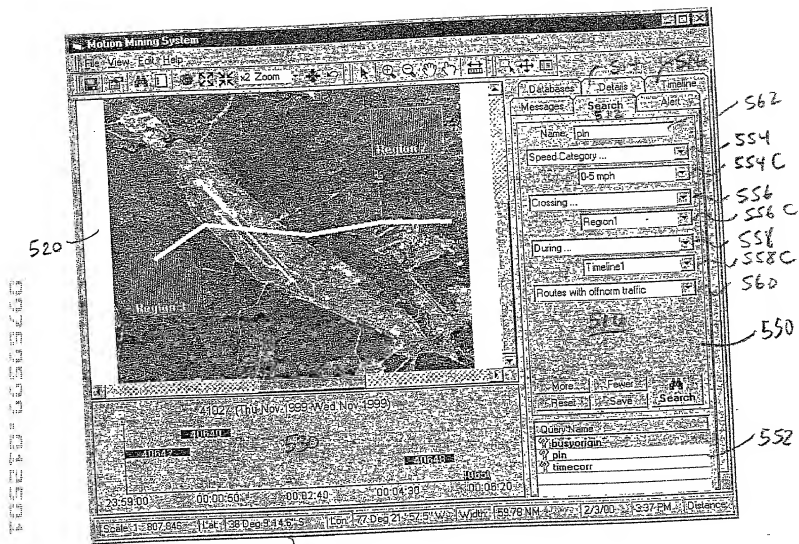


FIG 5

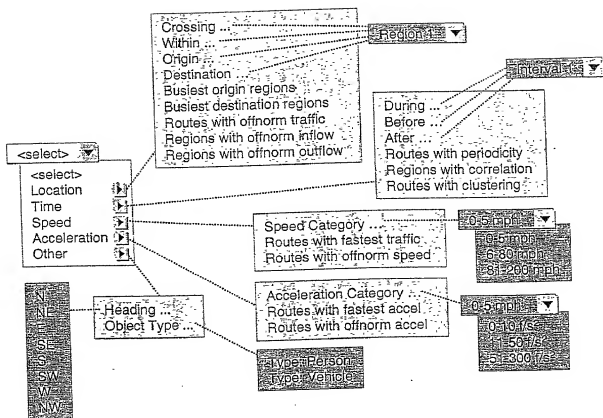


FIG. 6

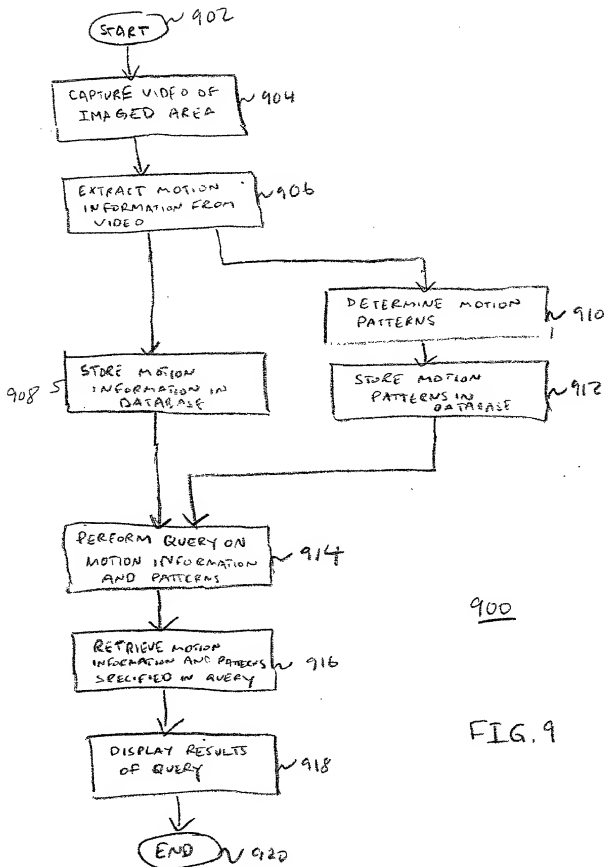


FIG. 9

1000 1002 1004 1006 1010 1012 1014 1016 1018

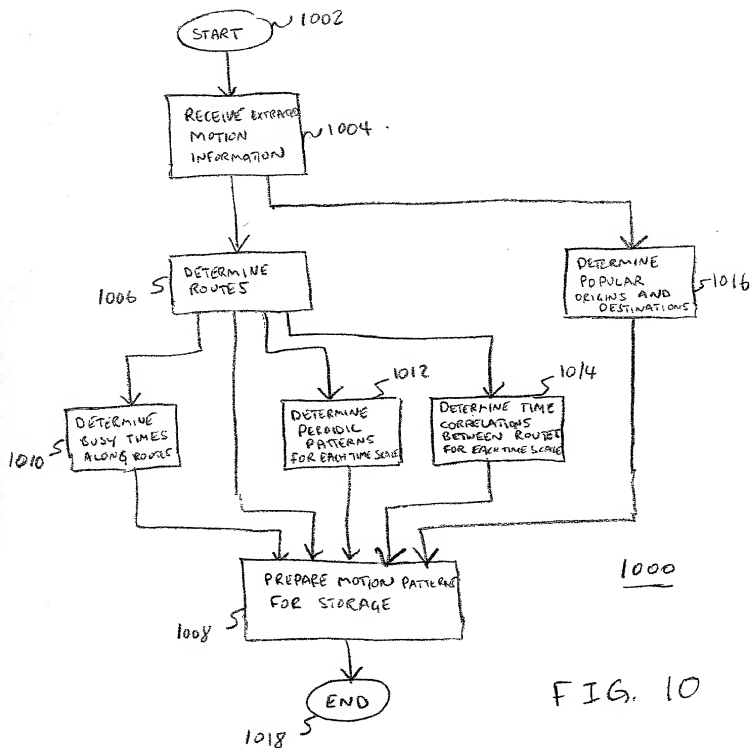


FIG. 10